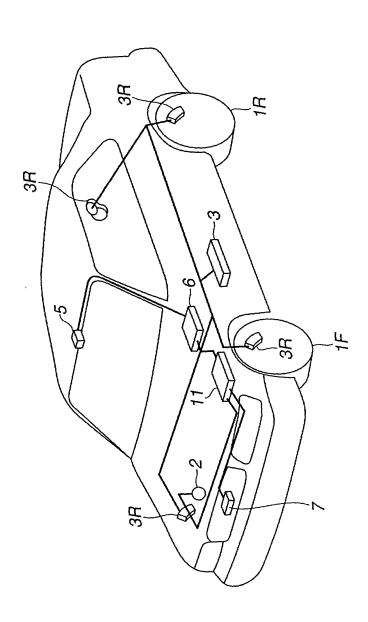
# ESTIMATING INTER-VEHICLE DISTANCE USING RADAR AND CAMERA Inventor(s): Tomohiro YAMAMURA Appl. No.: Unassigned





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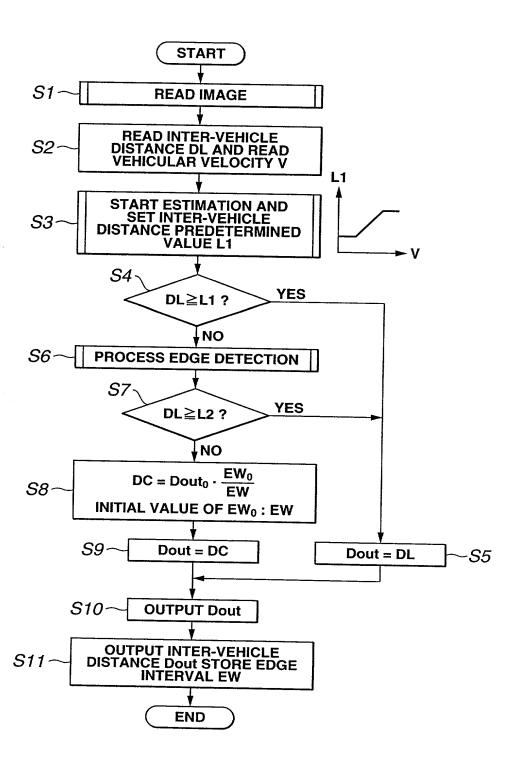
| ( | N.       |
|---|----------|
| _ | R        |
| C | 5        |
| _ | $\equiv$ |
| I | ı        |
|   |          |

|                           | NOT PROCESSED                   | LASER RADAR OUTPUT        |
|---------------------------|---------------------------------|---------------------------|
| L2~L1                     | ON OF<br>AL EDGE                | LASER RAD                 |
| 0~L2<br>OR RADAR LOST     | DETECTION OF<br>HORIZONTAL EDGE | CAMERA<br>OUTPUT          |
| INTER-VEHICLE<br>DISTANCE | DETECTION OF<br>EDGE BY CAMERA  | INTER-VEHICLE<br>DISTANCE |

ESTIMATING INTER-VEHICLE
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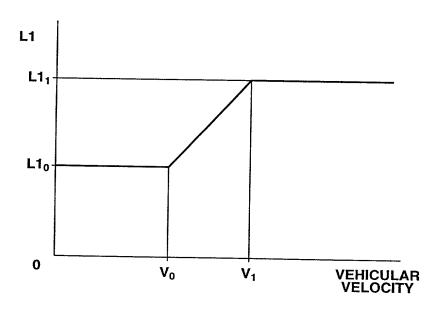
Inventor(s): Tomohiro YAMAMU Appl. No.: Unassigned

## FIG.3



Title: METHOD AND APPARATUS FOR ESTIMATING INTER-VEHICLE
DISTANCE USING RADAR AND
CAMERA
Inventor(s): Tomohiro YAMAMURA
Appl. No.: Unassigned

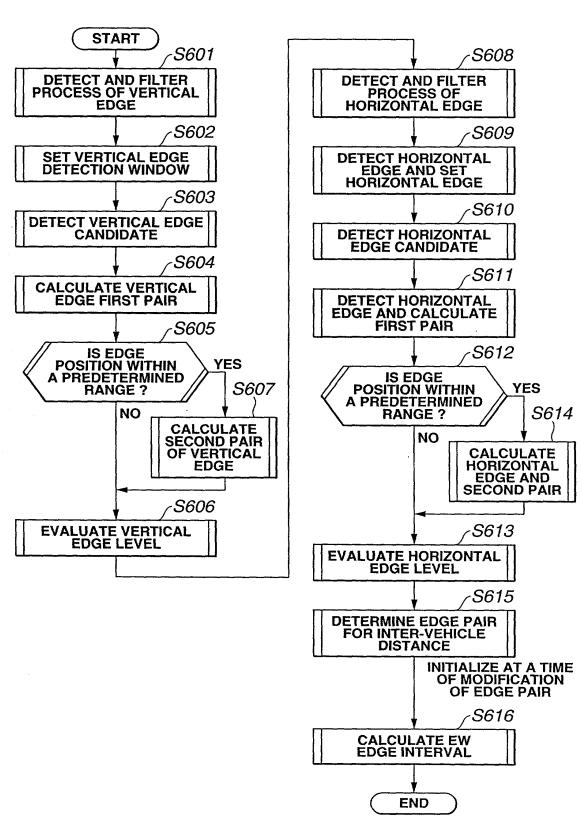
FIG.4



Inventor(s): Tomohiro YAMAMURA Appl. No.: Unassigned

Appr. No.: Onassigned

### FIG.5



Inventor(s): Tomohiro YAMAMURA
Appl. No.: Unassigned

FIG.6

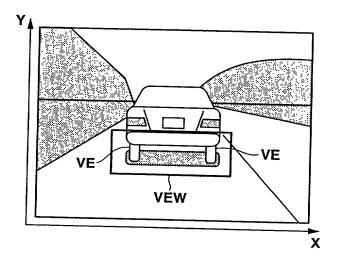
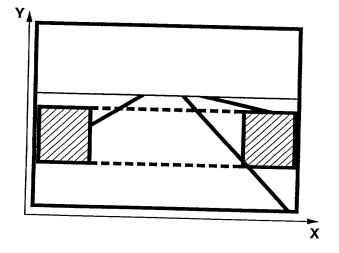


FIG.7



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FIG.8

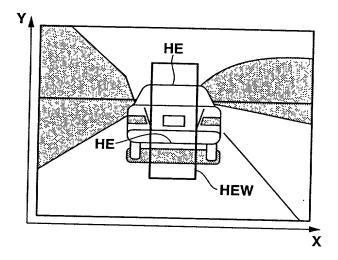
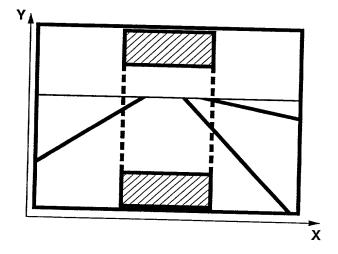
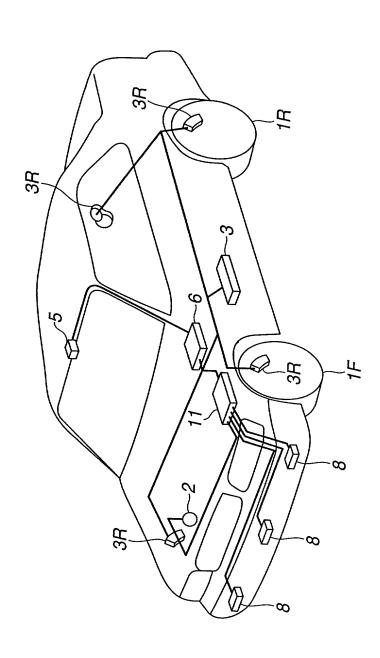


FIG.9



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## **HG.1**

| L4                        | NO PROCESS                  | NOT OUTPUT                          |
|---------------------------|-----------------------------|-------------------------------------|
| L3~L4                     | ECTION                      | OUTPUT<br>CAMERA                    |
| 0~L3                      | EDGE DETECTION              | OUTPUT<br>MICROWAVE<br>RADAR        |
| INTER-VEHICLE<br>DISTANCE | EDGE DETECTION<br>BY CAMERA | OUTPUT<br>INTER-VEHICLE<br>DISTANCE |

S30

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### **FIG.12**

